AMENDMENTS TO THE CLAIMS

1.   (Currently amended) A rendering device for generating a display image of an area around a vehicle for drive assistance, said rendering device comprising:

a reception part for receiving a current rudder angle of a steering wheel of ~~said~~ the vehicle from a rudder angle sensor fixed in the vehicle;

a derivation part for deriving an estimated path for ~~said~~ the vehicle to take based on the rudder angle received by said reception part; and

an image generation part for generating ~~said~~ the display image based on a captured image captured by an image capture device fixed in ~~said~~ the vehicle[[,]] and the estimated path derived by said derivation part, wherein

~~in said display image,~~ said image generation part overlays the estimated path ~~is overlaid~~ in the display image on an intermittent basis.

2.   (Currently amended) The rendering device according to claim 1, wherein ~~said~~ the display image includes an indicator which moves along ~~said~~ the estimated path in a ~~heading~~ direction ~~of said~~ in which the vehicle is heading towards.

3.   (Currently amended) The rendering device according to claim 1, wherein said image generation part overlays ~~said~~ the estimated path on ~~said~~ the captured image in a predetermined time period, but does not overlay the estimated path in other predetermined time periods.

4.   (Currently amended) A rendering device for generating a display image of an area around a vehicle for drive assistance, said rendering device comprising:

a first reception part for receiving a distance to an obstacle located around ~~said~~ the vehicle from a measuring sensor placed in the vehicle;

a first derivation part for deriving a farthest point for ~~said~~ the vehicle to move based on the distance received by said first reception part;

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a second reception part for receiving a current rudder angle of a steering wheel of ~~said~~ the vehicle from a rudder angle sensor fixed in the vehicle;

a second derivation part for deriving an estimated path for ~~said~~ the vehicle to take based on the rudder angle received by said second reception part; and

an image generation part for generating the display image based on a captured image captured by an image capture device fixed in ~~said~~ the vehicle, the farthest point derived by said first derivation part, and the estimated path derived by said second derivation part.

5.   (Currently amended) A rendering method of generating a display image of an area around a vehicle for drive assistance, said rendering method comprising:

a reception ~~step~~ operation of receiving a current rudder angle of a steering wheel of ~~said~~ the vehicle from a rudder angle sensor fixed in the vehicle;

a derivation ~~step~~ operation of deriving an estimated path for ~~said~~ the vehicle to take based on the rudder angle received in said reception ~~step~~ operation; and

an image generation ~~step~~ operation of generating the display image based on a captured image captured by an image capture device fixed in ~~said~~ the vehicle[[,]] and the estimated path derived in said derivation ~~step~~ operation, wherein

~~in said display image,~~ said image generation operation overlays the estimated path in the display image ~~is overlaid~~ on an intermittent basis.

6.   (Currently amended) The rendering method according to claim 5, wherein ~~said~~ the display image includes an indicator which moves along ~~said~~ the estimated path in a ~~heading~~ direction in which the ~~of said~~ vehicle is heading towards.

7.   (Currently amended) The rendering method according to claim 5, wherein ~~in~~ said image generation ~~step, said~~ operation overlays the estimated path ~~is overlaid~~ on ~~said~~ the captured image only in a predetermined time period, but does not overlay the estimated path in other predetermined time periods.

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8.	(Currently amended) A rendering method of generating a display image of an area around a vehicle for drive assistance, said rendering method comprising:

a first reception step operation of receiving a distance to an obstacle located around said the vehicle from a measuring sensor placed in the vehicle;

a first derivation step operation of deriving a farthest point for said the vehicle to move based on the distance received in said first reception step operation;

a second reception step operation of receiving a current rudder angle of a steering wheel of said the vehicle from a rudder angle sensor fixed in the vehicle;

a second derivation step operation of deriving an estimated path for said the vehicle to take based on the rudder angle received in said second reception step operation; and

an image generation step operation of generating the display image based on a captured image captured by an image capture device fixed in said the vehicle, the farthest point derived in said first derivation step operation, and the estimated path derived in said second derivation step operation.

9.	(Currently amended) A recording medium with a program recorded thereon for generating a display image of an area around a vehicle for drive assistance, said program comprising:

a reception step operation of receiving a current rudder angle of a steering wheel of said the vehicle from a rudder angle sensor fixed in the vehicle;

a derivation step operation of deriving an estimated path for said the vehicle to take based on the rudder angle received in said reception step operation; and

an image generation step operation of generating the display image based on a captured image captured by an image capture device fixed in said the vehicle[[,]] and the estimated path derived in said derivation step operation, wherein

in said display image, said image generation operation overlays the estimated path in the display image is overlaid on an intermittent basis.

10. (Currently amended) The recording medium with the program recorded ~~thereon~~ according to claim 9, wherein ~~said~~ the display image includes an indicator which moves along ~~said~~ the estimated path in a ~~heading~~ direction in which the ~~of said~~ vehicle is heading towards. .

11. (Currently amended) The recording medium with the program recorded thereon according to claim 9, wherein ~~in~~ said image generation ~~step, said~~ operation overlays the estimated path ~~is overlaid~~ on ~~said~~ the captured image only in a predetermined time period, but does not overlay the estimated path in other predetermined time periods.

12. (Currently amended) A recording medium with a program recorded thereon for generating a display image of an area around a vehicle for drive assistance, said program comprising:

a first reception ~~step~~ operation of receiving a distance to an obstacle located around ~~said~~ the vehicle from a measuring sensor placed in the vehicle;

a first derivation ~~step~~ operation of deriving a farthest point for ~~said~~ the vehicle to move based on the distance received in said first reception ~~step~~ operation;

a second reception ~~step~~ operation of receiving a current rudder angle of a steering wheel of ~~said~~ the vehicle from a rudder angle sensor fixed in the vehicle;

a second derivation ~~step~~ operation of deriving an estimated path for ~~said~~ the vehicle to take based on the rudder angle received in said second reception ~~step~~ operation; and

an image generation ~~step~~ operation of generating the display image based on a captured image captured by an image capture device fixed in ~~said~~ the vehicle, the farthest point derived in said first derivation ~~step~~ operation, and the estimated path derived in said second derivation ~~step~~ operation.

13. (Currently amended) A program for generating a display image of an area around a vehicle for drive assistance, said program comprising:

a reception ~~step~~ operation of receiving a current rudder angle of a steering wheel of ~~said~~ the vehicle from a rudder angle sensor fixed in the vehicle;

a derivation ~~step~~ operation of deriving an estimated path for ~~said~~ the vehicle to take based on the rudder angle received in said reception ~~step~~ operation; and

an image generation ~~step~~ operation of generating the display image based on a captured image captured by an image capture device fixed in ~~said~~ the vehicle[[,]] and the estimated path derived in said derivation ~~step~~ operation, wherein

~~in said display image,~~ said image generation operation overlays the estimated path in the display image ~~is overlaid~~ on an intermittent basis.

14.   (Currently amended) The program according to claim 13, wherein ~~said~~ the display image includes an indicator which moves along ~~said~~ the estimated path in a ~~heading~~ direction in which the ~~of said~~ vehicle is heading towards.

15.   (Currently amended) The program according to claim 13, wherein ~~in~~ said image generation ~~step, said~~ operation overlays the estimated path ~~is overlaid~~ on ~~said~~ the captured image only in a predetermined time period.

16.   (Currently amended) A program for generating a display image of an area around a vehicle for drive assistance, said program comprising:

a first reception ~~step~~ operation of receiving a distance to an obstacle located around ~~said~~ the vehicle from a measuring sensor placed in the vehicle;

a first derivation ~~step~~ operation of deriving a farthest point for ~~said~~ the vehicle to move based on the distance received in said first reception ~~step~~ operation;

a second reception ~~step~~ operation of receiving a current rudder angle of a steering wheel of ~~said~~ the vehicle from a rudder angle sensor fixed in the vehicle;

a second derivation ~~step~~ operation of deriving an estimated path for ~~said~~ the vehicle to take based on the rudder angle received in said second reception ~~step~~ operation; and

an image generation ~~step~~ operation of generating the display image based on a captured image captured by an image capture device fixed in ~~said~~ the vehicle, the farthest point derived in

said first derivation ~~step~~ operation, and the estimated path derived in said second derivation ~~step~~ operation.